This listing of claims will replace all prior versions, and listings, of claims in the application:

The Status of the Claims

1.   (Previously Presented) A method of mobile device control comprising:

moving a surrogate under wireless control by a user;

during the moving, detecting unsuitable degradation of wireless communications of the wireless control; and

in response to the detecting and while the surrogate is still receiving the wireless communications, autonomously moving the surrogate to provide suitable wireless communications of the wireless control;

wherein the detecting comprises comparing a performance parameter associated with the wireless communications with a threshold.

2.   (Currently Amended) The method as claimed in claim 1 additionally comprising[[:]] autonomously moving the surrogate along a previously determined route.

3.   (Currently Amended) The method as claimed in claim 1 wherein[[:]] autonomously moving the surrogate to provide suitable wireless communications of the wireless control occurs after the passage of [[a]] the period of time following the detecting of the degradation; and

the method further comprises after the detecting of the unsuitable degradation, the surrogate loitering near a location where the unsuitable degradation was detected during the passage of the period of time.

4-5.   (Cancelled)

6. (Currently Amended) The method as claimed in claim 1 wherein:

the autonomously moving of the surrogate uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

the autonomously moving of the surrogate uses waypoints back along a forward movement path for backtracking movement.

7. (Currently Amended) A method of mobile telepresencing comprising:

moving a surrogate under real-time wireless control by a user;

autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time;

while the surrogate is autonomously moving, activating a human perceptible indicator which is perceptible to humans in the presence of the surrogate; and

prior to autonomously moving the surrogate, determining that the loss of the wireless control has persisted for the period of time, wherein the period of time is at least two seconds.

8. (Cancelled)

9. (Currently Amended) The method as claimed in claim 7 wherein:

the losing of wireless control includes degradation of the control to a threshold level; and

the autonomously moving of the surrogate to regain wireless control occurs after the period of time.

10. (Currently Amended) The method as claimed in claim 7 wherein[[:]] the autonomously moving of the surrogate includes:

backtracking while measuring distance and avoiding collisions by the surrogate;

stopping the surrogate for an obstacle; and

resuming backtracking after removal of the obstacle.

11.   (Cancelled)

12.   (Currently Amended) The method as claimed in claim 7 wherein:

the autonomously moving of the surrogate uses logged information of forward

movement using at least one of dead reckoning, odometry, directional measurement,

differential wheel rotation, or a combination thereof;

the autonomously moving of the surrogate uses a slower speed than a forward

speed; and

the autonomously moving the surrogate uses waypoints back along a forward

movement path for backtracking movement considering the slower speed of

backtracking.

13.   (Currently Amended) A mobile device control system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system on the surrogate for moving to move the

surrogate to regain wireless control independently of the wireless control after passage

of a nonzero amount of time following a loss of the wireless control;

wherein the computer/transceiver system is configured to move the surrogate

after the computer/transceiver system has determined that the loss of wireless control

has persisted for the non-zero amount of time; and

the computer/transceiver system is to detect the loss of the wireless control, to

configure the surrogate to loiter for the non-zero amount of time following the loss of the

wireless control near a location at which the loss of the wireless control was detected, and to monitor for return of the wireless control during the non-zero amount of time.

14.   (Cancelled)

15.   (Currently Amended)   The system as claimed in claim 13 wherein[[:]] the computer/transceiver system is ~~configured~~ to autonomously move the surrogate to regain wireless control after the surrogate remains stationary for the non-zero amount of time unless wireless control has been regained.

16.   (Currently Amended) The system as claimed in claim 13 wherein[[:]] the computer/transceiver system ~~for autonomously moving~~ is to move the surrogate ~~includes~~ by measuring a distance and avoiding a collision. ~~collisions by the surrogate.~~

17.   (Cancelled)

18.   (Currently Amended) The system as claimed in claim 13 wherein:

the computer/transceiver system is to use ~~uses~~ logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof; and

the computer/transceiver system is to calculate ~~calculates~~ waypoints back along a forward movement path for backtracking movement.

19.   (Currently Amended) A mobile telepresencing system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system configured to determine when the wireless control is lost and, responsive to the determining, to autonomously move the surrogate to an area not currently receiving adequate coverage of the wireless control, but in which the

surrogate previously experienced adequate coverage of the wireless control, and wait in the area until adequate coverage of the wireless control is regained.

20.　(Currently Amended)　The system as claimed in claim 19 wherein[[:]] the computer/transceiver system is configured to autonomously move the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

21.　(Currently Amended)　The system as claimed in claim 19 wherein:

the computer/transceiver system is ~~configured~~ to determine degradation of the wireless control to a threshold level; and

the computer/transceiver system is ~~configured~~ to autonomously move the surrogate to regain wireless control after a period of time.

22.　(Currently Amended)　The system as claimed in claim 19 wherein[[:]] the computer/transceiver system includes:

backtracking means for measuring a distance and avoiding ~~collisions~~ a collision by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for resuming backtracking after removal of the obstacle.

23.　(Cancelled)

24.　(Currently Amended)　The system as claimed in claim 19 wherein:

the computer/transceiver system ~~uses~~ is to use logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, or a combination thereof for backtracking;

the computer/transceiver system ~~provides~~ is to provide a slower speed than a

forward speed for backtracking by the surrogate; and

the computer/transceiver system ~~uses~~ is to use waypoints back along a forward

movement path for backtracking movement considering the slower speed of

backtracking.

25.　(Cancelled)

26.　(Currently Amended) The method as claimed in claim 1 wherein[[:]] the

detecting comprises determining that a current non-zero data rate at which the

surrogate is successfully transmitting data via the wireless communications is less than

a desired data rate.

27.　(Currently Amended) The method as claimed in claim 26 further

comprising[[:]] prior to the detecting, wirelessly transmitting a video signal at or above

the desired data rate from the surrogate to the user.

28.　(Currently Amended) The method as claimed in claim 10 further

comprising[[:]] prior to the resuming of the backtracking, the surrogate ~~sensing~~ is to

sense removal of the obstacle,~~; and~~ wherein the resuming is responsive to the sensing.

29.　(Previously Presented) The method as claimed in claim 1 wherein the

detecting comprises determining that a current transmission delay associated with

packets received by the surrogate is greater than an acceptable transmission delay.

30.　(Currently Amended) The system [[of]] as claimed in claim 13 wherein ~~the~~

~~computer/transceiver system is configured to detect the loss of the wireless control and~~

~~to configure the surrogate to remain~~ the loitering comprising remaining substantially

stationary for the non-zero amount of time following the loss of the wireless control near a location at which the loss of the wireless control was detected.

31.   (Currently Amended) The method [[of]] as claimed in claim 7 wherein the surrogate comprises the human perceptible indicator.

32.   (Cancelled)

33.   (Currently Amended) The system [[of]] as claimed in claim 19 wherein the computer/transceiver system is configured to loiter in the area for the wireless control to return.

34.   (Currently Amended) The method [[of]] as claimed in claim 10 wherein the resuming backtracking comprises automatically without user intervention resuming backtracking.

35.   (Currently Amended) The system [[of]] as claimed in claim 22 wherein the means for resuming backtracking after removal of the obstacle comprises means for automatically without user intervention resuming backtracking after removal of the obstacle.

36.   (Cancelled)

37.   (Currently Amended) The system [[of]] as claimed in claim 13 wherein the computer/transceiver system is configured to determine that a first non-zero data rate at which the surrogate is successfully transmitting data via the wireless control at a first moment in time is less than a desired data rate and as a result of the determining, is to move the surrogate so that the surrogate transmits data via the wireless control at a second non-zero data rate that is greater than or equal to the desired data rate at a second moment in time after the first moment in time.